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TITLE: SELF-DRIVING METHOD OF TRUCK

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ABSTRACT:

PURPOSE: To set easily a driving target and to improve greatly the working
efficiency by keeping the differences of angles formed by the straight lines
connecting markers and left and right image sensors and center line of a truck
within a set range respectively.

CONSTITUTION: Markers 6 and 7 are set on a virtual driving target (lc) with a
prescribed distance (y) secured between them. The images of markers 6 and 7 are
projected to a pair of image sensors 4 respectively. These sensors 4 detect the
right-left displacement distance to optical axes (lb) of those images. Based on the
result of this detection, each camera 5 calculates successively at the angles θ_{1a},
θ_{1b}, θ_{2a} and θ_{2b} formed by markers 6 and 7 respectivly through an automatic
controller. Then an automatic controller controls an automatic steering device to a
driving device 1 so as to maintain relations $\theta_{1a}-\theta_{1b}\leqq\epsilon_1$ and $\theta_{2a}-\theta_{2b}\leqq\epsilon_2$
in terms of the absolute values of said angles. Thus the direction and the right-
left position can be corrected for a truck body A.